REMARKS

The Final Office Action dated November 16, 2009 has been reviewed and carefully considered. Claims 1-4 and 8-11 remain present in the application. Claims 1, 8, 10 and 11 are the independent claims, each of which having been amended. Support for these amended claims can be found, at least, in the specification on page 2, lines 17-23, indicating that a depth difference is created in a depth map on an edge, i.e. with respect to the adjacent sides of the edge; page 2, lines 24-25, indicating that the depth difference is associated with the edge which may be more than one pixel; Fig. 4B, depicting an exemplary depth map wherein the depth values of edges are less than those of their surroundings on either side of the edge (i.e. darker); page 9, lines 11-25 corresponding with Fig. 5A, 5B and 5, depicting weighting functions for use in generating depth map values, which clearly indicate that: the edge when weighted will have a depth value less than that of the areas around the edge (Fig. 5A-5C) and the depth values on either sides of the edge need not be identical (Fig. 5C). Reconsideration of the above-identified application, as amended and in view of the following remarks, is respectfully requested.

Claims 1, 10 and 11 stand rejected under 35 U.S.C 102(e) as being anticipated by Fujimura et al (US PAP 2005/0031166). Applicants respectfully traverse. Claims 1-4 and 1-11 stand rejected under 35 U.S.C 102(e) as being anticipated by Neumann et al (US PAP 2004/0105573). Applicants respectfully traverse.

Amended claim 1 recites the limitation of "depth map generation means (104) for generating a depth map for the input image on basis of the edge, by generating a first group of elements of the depth map corresponding to the edge having a first depth value, related to a viewer of the multi-view image, a second group of elements of the depth map corresponding to a region of the input image, being located adjacent to the edge *on a first side,* having a second depth value, related to the viewer of the multi-view image, *and a third group of elements of the depth map corresponding to a region of the input image, being located adjacent to the edge on a second side, having a third depth value, related to the viewer of the multi-view image.*"

As previously noted Fujimura, teaches "a depth image is visually represented with variations in the pixel intensity based on the depth value, that is the objects closer to the camera appear brighter and progressively darker until the background outside a depth window is shown as black…and a stream of depth images or frame are produced…the hybrid image data includes depth data for each pixel…" see page para. [0026]. Nothing therein discloses edge detection nor is it implicit.

As previously noted Neumann, teaches building sections can be classified into several groups, in which appropriate building primitive are defined… the system can automatically determine the EOI [element of interest] information using a heuristic that processes standard deviation and derivative of the height data. The flat-roof is a typical roof type of man-made buildings, which can be modeled using the plane-primitive group, including 3D plan… a 3D plan primitive can be determined by two reference points and

an orientation... with the two reference points, the system automatically estimates all corners of the building rood based on the global direction...[and then] detecting the roof edges using a depth discontinuity constraint..." See para. [0043] – [0045]. Moreover, Neumann uses various (known) techniques (including depth discontinuity constraints, 8-neighbors connectivity algorithm, Delaunay triangulation).

Applicants can find nothing in either Fujimura or Neumann that teaches depth map generation means for generating a depth map for the input image on basis of the edge, by generating a first group of elements of the depth map corresponding to the edge having a first depth value, related to a viewer of the multi-view image, a second group of elements of the depth map corresponding to a region of the input image, being located adjacent to the edge *on a first side,* having a second depth value, related to the viewer of the multi-view image, *and a third group of elements of the depth map corresponding to a region of the input image, being located adjacent to the edge on a second side, having a third depth value, related to the viewer of the multi-view image,* as in amended independent claims 1, 8, 10 and 11.

A claim is anticipated only if each and every element recited therein is expressly or inherently described in a single prior art reference. Fujimura and/or Neumann cannot be said to anticipate the present invention, because Fujimura and/or Neumann fail to disclose each and every element recited.

Having shown that Fujimura and/or Neumann fail to disclose each and every element claimed, applicant submits that claims 1, 8, 10-11 are allowable over Fujimura and/or Neumann. Applicants respectfully request reconsideration, withdrawal of the rejection and allowance of independent claims 1, 8, 10-11.

With regard to the remaining claims, each of these claims depends from one of the independent claims, and, hence, is also not unpatentable over Fujimura and/or Neumann by virtue of its dependency upon an allowable base claim.

For all the foregoing reasons, it is respectfully submitted that all the present claims are patentable in view of the cited references. Entry of this amendment and a Notice of Allowance is respectfully requested.

Respectfully submitted,

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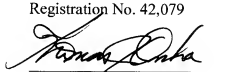

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